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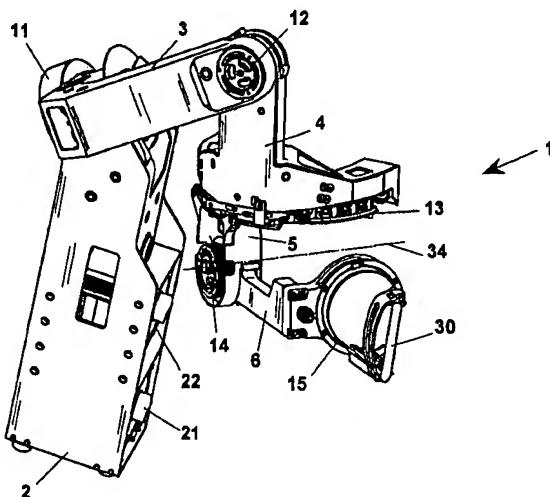
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(54) Title: EKOSKELETON INTERFACE APPARATUS



(57) Abstract: An exoskeleton interface apparatus comprises five rigid links (2-6) arranged in series, capable of rotating reciprocally at the respective ends for monitoring angular movements of the arm, of the forearm and of the wrist of an user (60) and having at the tip an handgrip (30) for engaging with the user (60) by reflecting a force feedback. The rigid links (2-6) can rotate at their ends about rotational joints (11-14) having rotational axes (31-34) incident in the intersection point of the physiological axes of the shoulder. The rotational joints (11-14) are brought into rotation about the respective rotational axes (31-34) by means of respective motors (21-24), for example servo-motor such as torque motors. All the motors (21-24) are mounted on the fixed base link (2) in order to minimize the mass of the parts in movement and the inertia reflected on the user (60). A plurality is provided of idle pulleys (50) spatially arranged in space (figure 6) for orienting the tendons (41-44), which brake the free movement of the relative rotational joint, responsive to signals corresponding to constraints on the slave in case of Teleoperation or to constraints created by Virtual reality systems.

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